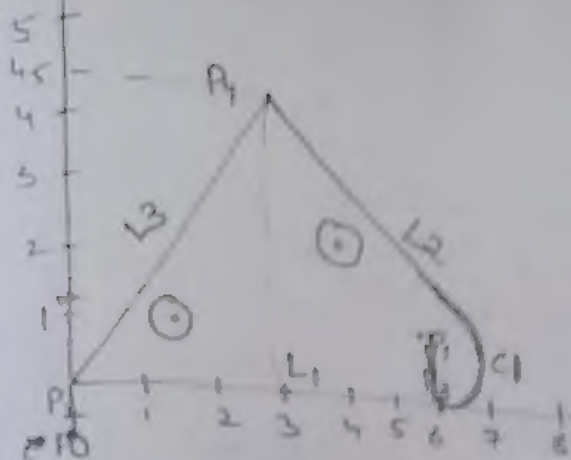Ex.1

PO = POINT/0, -10, 0

P1 = POINT/60, 1.125, 0

P2 = POINT/0.0, 0.0, 0.0

P3 = POINT/6.0, 0, 0]

P4 = POINT/3.0, 4.5, 0

L1 = LINE/P2, P3

L2 =

C1 = CIRCLE/CENTER, P1, RADIUS, 1.125

L2 = LINE/ P4, TANTO, C1

L3 = LINE/P2, P4

PL1 = PLANE/P2, P3, P4

MOTION STATEMENTS

The general form of a motion statement is

motion command / descriptive data

Ex:- GOTO / P1

↓ 1st section (motion command) which tells the tool what to do

↓ 2nd section

(Descriptive data, which tell the tool where to go)

- The tool is commanded to go to point P1, which has been defined in a preceding geometry state...

- At the beginning of the motion statements, the tool may given a starting point, called as Target point, the location where the operator has positioned the tool the start of the job

  FROM / TARG

Ex - FROM / -20, -20, 00

  GOTO/P2
  GOTO/20, 70, 00

- In the 1st statement, P2 is the destination of the tool. In the 2nd ", tool is instructed to go to x=2, y=...

- GODLTA command → Specifies an incremental motion the tool.

Ex - GODLTA/20, 70, 00

  GODLTA Command → Useful for drilling.

Ex:-
  P1 = POINT/10, 20, 0
  P2 = POINT/10, 10, 0
  P3 = POINT/35, 15, 0
  P0 = POINT/-10, 30, 20
  FROM /P0
  GOTO/P1
  GODLTA/0, 0, -10
  GODLTA/0, 0, +10
  GOTO/P2
  GODLTA/0, 0, -10
  GODLTA/0, 0, +10
  GOTO/P3

  GODLTA /0, 0, -10
  GODLTA /0, 0, +10
  GOTO/P0

Cutter

Drive Surface

Check Surface

Relative tool movement

Part Surface